

**FIG. 2**

$$M = M\_ANCHOR * M\_RESIZE * M\_SKEW * M\_ROTATE * M\_TRANSLATE$$

$$M\_ANCHOR = \begin{bmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ XANCHOR & YANCHOR & 1 \end{bmatrix}$$

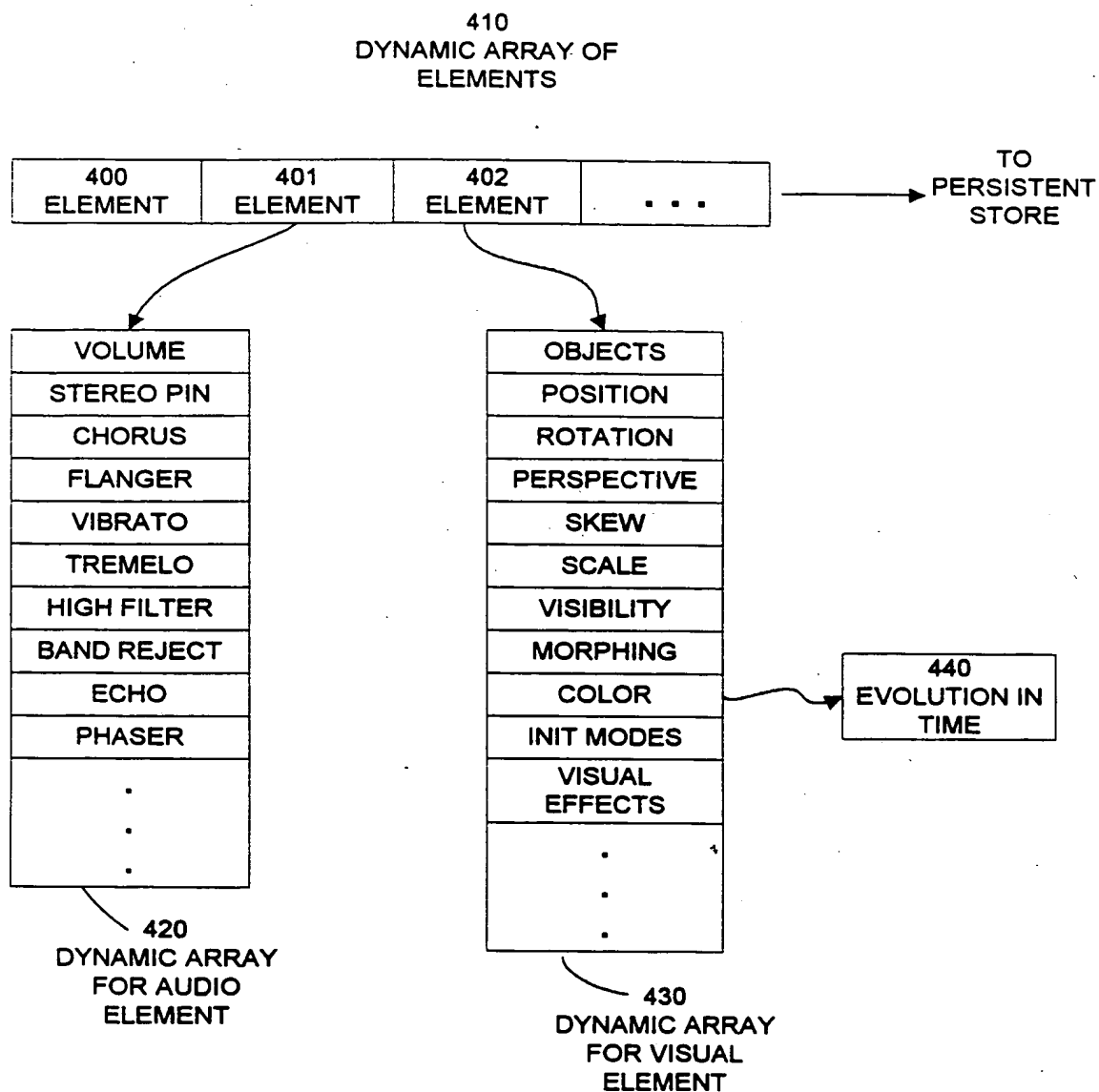
$$M\_RESIZE = \begin{bmatrix} XRESIZE & 0 & 0 \\ 0 & YRESIZE & 0 \\ 0 & 0 & 1 \end{bmatrix}$$

$$M\_SKEW = \begin{bmatrix} 1 & YSKEW & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 1 \end{bmatrix}$$

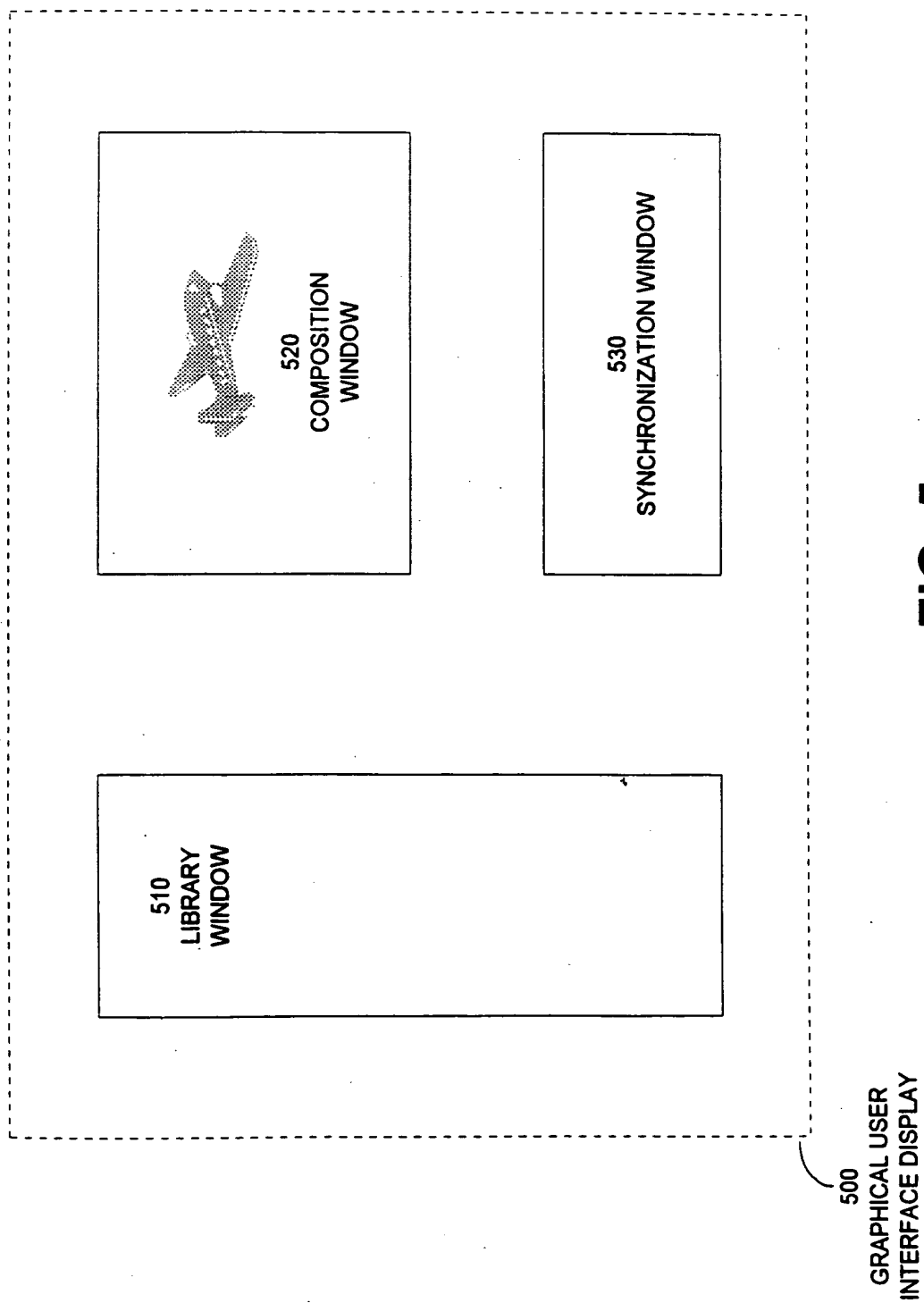
$$M\_ROTATE = \begin{bmatrix} \cos(\beta) & \sin(\beta) & 0 \\ -\sin(\beta) & \cos(\beta) & 0 \\ 0 & 0 & 1 \end{bmatrix}$$

$$M\_TRANSLATE = \begin{bmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ XPOSITION & YPOSITION & 1 \end{bmatrix}$$

**FIG. 3**



**FIG. 4**

[illegible]

**FIG. 5**

600 602 604 606 608 610 612 614 616

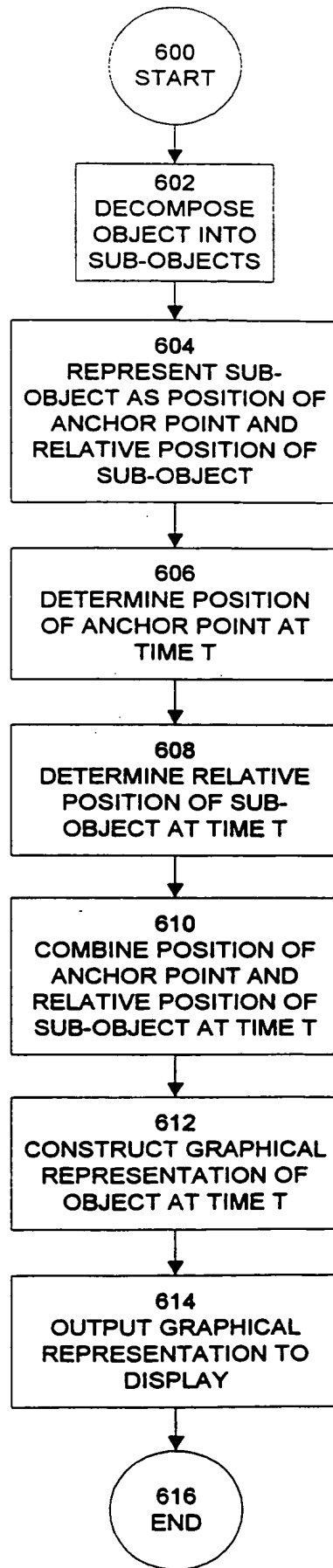
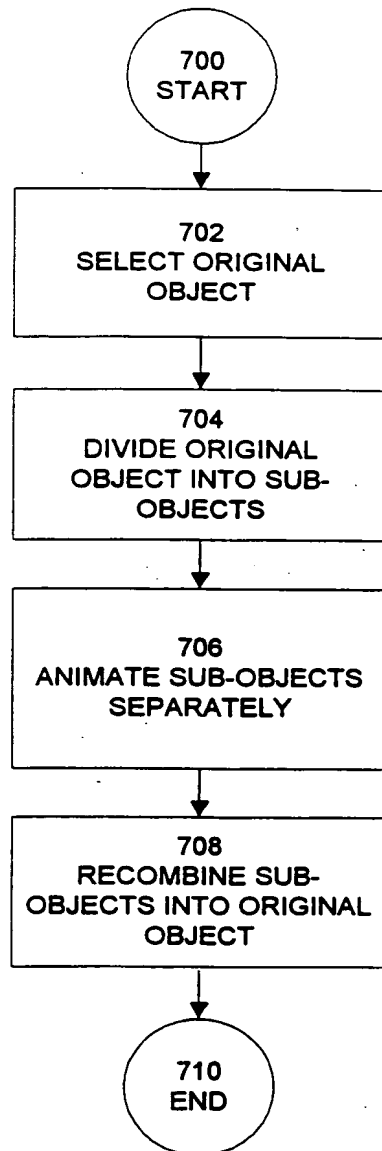


FIG. 6



**FIG. 7**

FIG. 8 is a block diagram of a system 800.

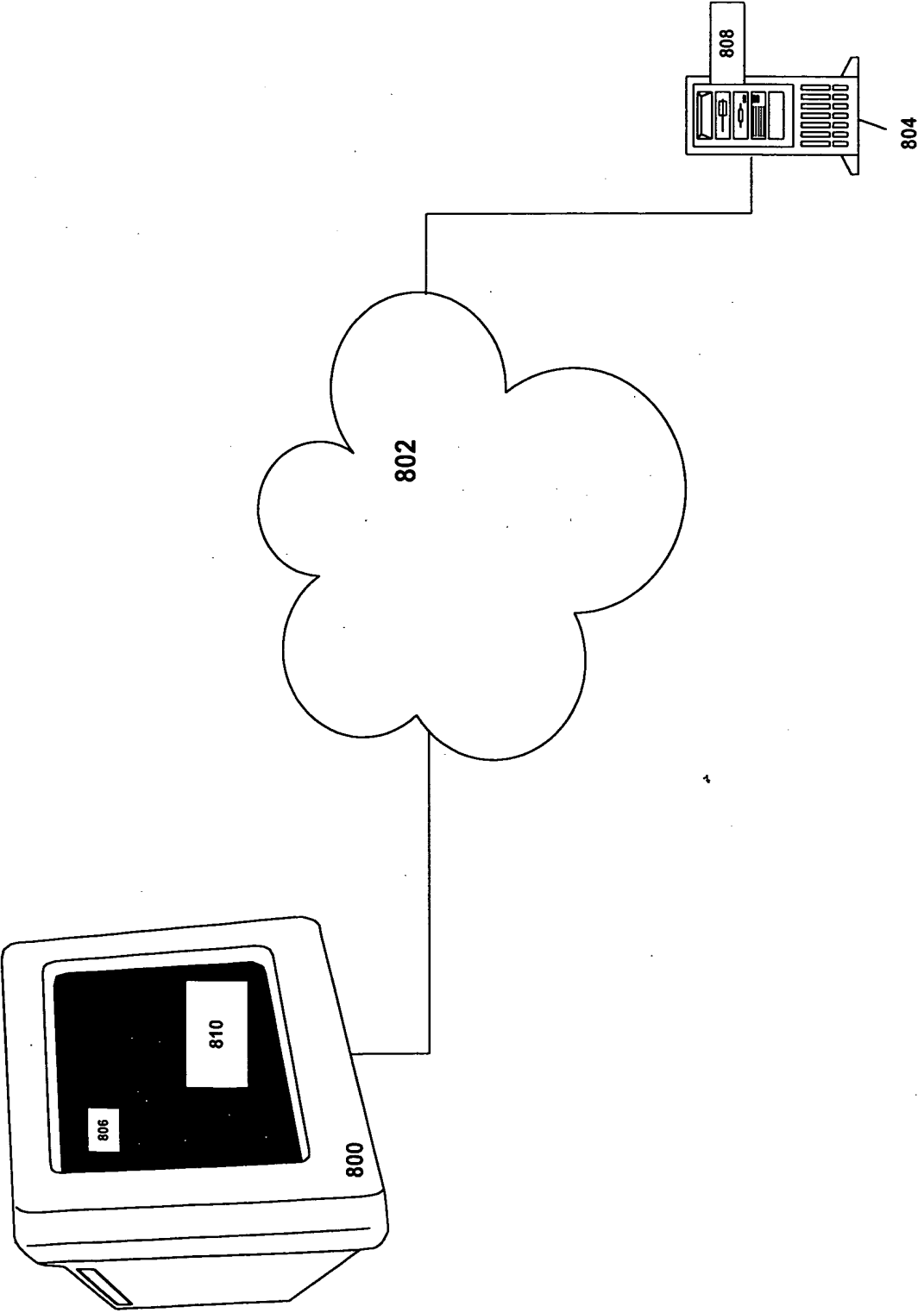


FIGURE 8



